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amended.  
sub  
C1  
conced.*

non-rotational, relative linear movement between the stator and the magnetic assembly and at least one of the plurality of coils and the plurality of magnetic poles are arranged to describe a helical path about the axis of the transducer whereby the magnetic circuit includes a helical component.

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### REMARKS

All claims have been rejected alone, or in part, as anticipated or obvious in view of Kling. These rejections are respectfully traversed.

Independent claim 1 has been amended to clarify that the mechanical transducer defined by claims is specifically designed for non-rotational, relative linear movement between the operative parts. A marked-up copy of claim 1 reflecting the amended material is attached. Neither Kling alone, or in combination with the other references, disclose or suggest a transducer for linear movement where the magnetic circuit includes a helical component. In Kling, the stator and the magnetic assembly of Fig. 25 are arranged for helical movement not for relative linear movement. In fact, the electromagnetic device of Kling is incapable of linear movement, without rotational movement, as this would result in misalignment of the poles. Although the device of Fig. 26 does give rectilinear motion, the only helical feature of this embodiment is the positioning of individual pairs of outer pole-